



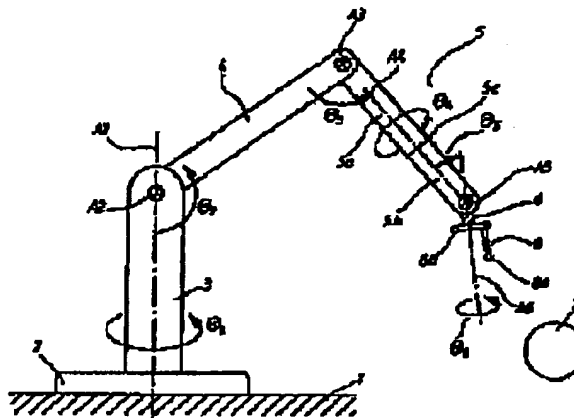


INDUSTRIAL ROBOT CALIBRATION METHOD AND INDUSTRIAL ROBOT DEVICE**Publication number:** JP7186073**Publication date:** 1995-07-25**Inventor:** JIYON ERITSUKU SUNERU**Applicant:** ASEA BROWN BOVERI**Classification:****- International:** B25J9/16; B25J9/22; B25J9/16; B25J9/22; (IPC1-7);
B25J9/10; G05B19/18; G12B5/00**- european:** B25J9/16T5**Application number:** JP19940279380 19941114**Priority number(s):** SE19930003757 19931115**Also published as:** EP0655301 (A1)
 US5687293 (A1)
 EP0655301 (B1)
 SE501867 (C2)[Report a data error here](#)**Abstract of JP7186073**

PURPOSE: To provide a calibration method and a device allowing automatic calibration with high precision without requiring a large-scale additional apparatus for calibration.

CONSTITUTION: In this calibration method, a calibration tool 8 supported by a robot hand 6 is brought into contact with a calibration body 7 having a known radius. Thereafter, the output signals from the position transducers of robot axes are read and stored. This method is repeated a plurality of times with different robot configurations. The calibration parameters of the robot are calculated based on the kinetic equations of the robot, a model of the relationship between axial position and position transducer signal, the known radius of the calibration body, and the read and stored position transducer signals.

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